**Amendments to the Specification:**

Please amend the specification as follows:

**Page 1**: After the title, insert:

--INCORPORATION BY REFERENCE

This is a 371 national phase application of PCT/IB04/04048 filed 09 December 2004, claiming priority to Japanese Patent Application No. 2003-425109 filed 22 December 2003, the contents of which are incorporated herein by reference.—

**Pages 3-4**: Replace paragraphs **[0008]** and **[0009]** with the following amended paragraphs:

**[0008]** In view of the above, ~~it is an object of the invention to provide~~ a constant velocity universal joint in which a thrust force generated during rotation can be suppressed is provided.

**[0009]** An aspect of the invention relates to a constant velocity universal joint including (a) a hollow outer joint member in which plural guide grooves extending in an axial direction of the outer joint member are formed in an inner peripheral surface in an axial direction, and which is connected to a first shaft; (b) an inner joint member which is connected to a second shaft, and which is housed in the outer joint member; (c) plural leg shafts provided in the inner joint member, each of which protrudes in a radial direction of the second shaft, and in each of which a convex sphere is formed in a tip portion; [[and]] (d) ~~a roller unit including~~ an inner roller in which a concave sphere that is engaged with the convex sphere of each of the leg shafts is formed in an inner peripheral surface, [[and]] (e) an outer roller which is housed in each of the guide grooves of the outer joint member so as to be slidable, (f) a rolling body which is provided between the inner roller and the outer roller ~~being~~ so that the inner roller and the outer roller are movable with respect to each other in an axial direction of the inner roller and the outer roller ~~through a rolling body~~, wherein each of the leg shafts and the inner

roller can be oscillated with respect to each other, wherein [[(e)]] (g) the leg shafts and the inner roller can be oscillated with respect to each other. The constant velocity universal joint is characterized in that [[(f)]] (h) a cylindrical surface is formed in a radially outer surface of the outer roller; [[(g)]] (i) a flat engagement surface which is engaged with the cylindrical surface of the outer roller is formed in a lateral surface of each of the guide grooves of the outer joint member; and [[(h)]] (j) the cylindrical surface of the outer roller satisfies the following two equations.

(equation 3) $W1 > PCR(1 - \cos\theta) / 2 + \mu_3 R_3 + \mu_2 R1$

(equation 4) $W2 > 3PCR(1 - \cos\theta) / 2 - \mu_3 R_3 + \mu_2 R1$

In these equations, W1 indicates a length in an axial direction of the cylindrical surface from a center of the cylindrical surface in the axial direction to an end portion of the cylindrical surface on an outer peripheral side of the outer joint member, W2 indicates a length in the axial direction of the cylindrical surface from the center of the cylindrical surface in the axial direction to an end portion of the cylindrical surface on a joint center side of the outer joint member, PCR indicates a distance from an axis of the inner joint member to a center of the convex sphere of each of the leg shafts, $\theta$ indicates a required maximum joint angle, R1 indicates a radius of the cylindrical surface of the outer roller, $R_3$ indicates a radius of the concave sphere of the inner roller, $\mu_2$ indicates a friction coefficient when the inner roller is moved with respect to the outer roller in an axial direction of the inner roller [[(16)]], and $\mu_3$ indicates a friction coefficient between the convex sphere of each of the leg shafts and the concave sphere of the inner roller.